

ABSTRACT OF THE DISCLOSURE

In a biped robot control system, stereoscopic images captured by CCD cameras are analyzed, the analyzed images are then utilized to detect presence of any moving object around the robot and if it present, to calculate moving object information, and based on the calculated moving object information, it is determined whether or not walking of the robot needs to be stopped. If it is determined to be stopped, the robot is controlled to stop within a period that brings the travel distance at stopping (distance moved between image capture by the CCD cameras and stopping of robot walking) to within a predetermined distance. With this, when the robot approaches a moving object during walking, it can be stopped within the predetermined distance to avoid collision with the moving object.